

ABSTRACT OF THE DISCLOSURE

An impact absorbing mechanism, provided to a foot 5 of an extremity of each of two movable legs 2 of a bipedal walking robot 1 having the two movable legs 2, includes: an upper base plate 5-a joined to a foot joint 4 of each of the movable legs 2; a lower base plate 5b positioned below the upper base plate, and being opposite to the upper base plate; and three elastic members 6 anisotropic in terms of elasticity, which are arranged at equal intervals in the circumferential direction about the yaw axis YA extending in a direction perpendicular to the upper base plate 5a, between the upper base plate 5a and the lower base plate 5b, each of which allows the lower base plate 5b to make elastic displacement relative to the upper base plate 5a in the same direction as axis YA extends, while each of which inhibits the lower base plate 5b from making elastic displacement relative to the upper base plate 5a in directions orthogonal to the yaw axis direction, and which join the upper base plate 5a and the lower base plate 5b elastically. This can simplify a calculation by a CPU concerning control of the walking of the walking robot. This can prevent disturbance, which would otherwise occur due to the friction resistance stemming from the physical interference by the rigid members. In addition, this can prevent the 6-axis force sensor from being broken, and can also prevent an equivalent to the breakage.